

# analysis all #4459-0513-14

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1. 准备
2. plot computed\_path\*.txt
  1. dvr\_0513\_rs\_1\_left
  2. dvr\_0513\_rs\_1\_right
  3. dvr\_0513\_mode10\_2\_left
  4. dvr\_0513\_mode10\_1\_right

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## 1. 准备

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TS: 2c0ad6575fbbd4bc69bc22704fb27838276aaa5f 【0513】

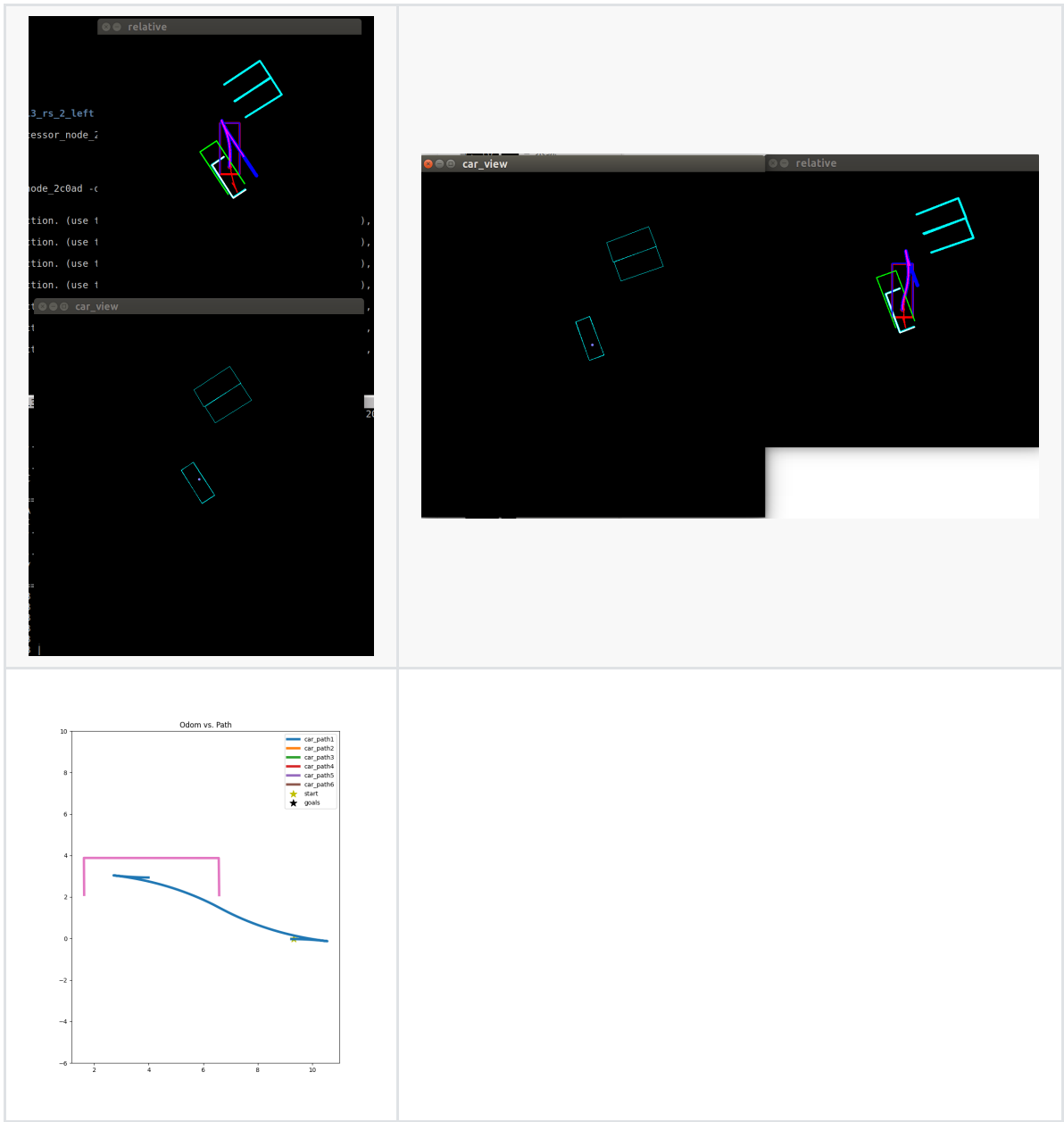
TS: d141d5b02b4172c282476a9f2049934ffd7c70eb 【0514】

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## 2. plot computed\_path\*.txt

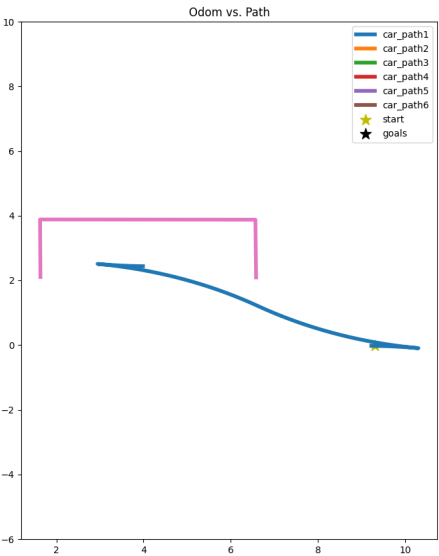
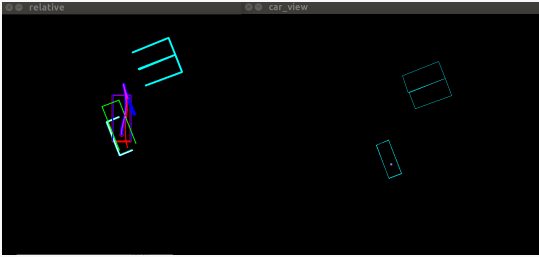
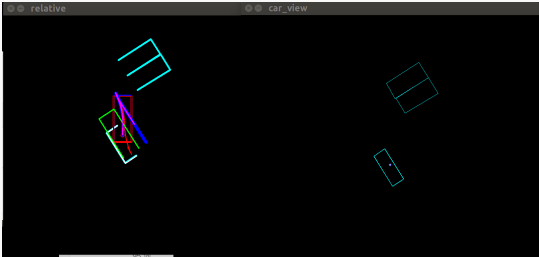
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### 1. dvr\_0513\_rs\_1\_left

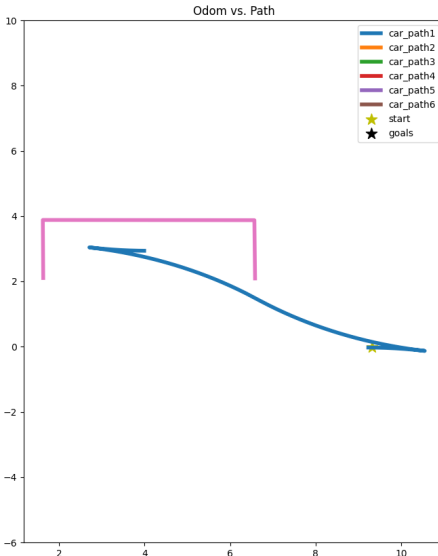
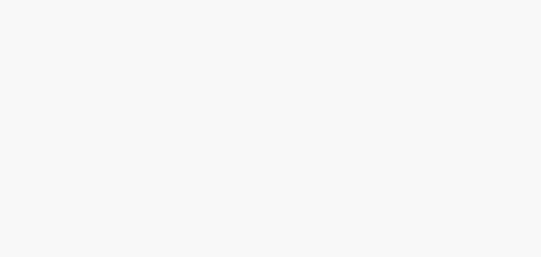
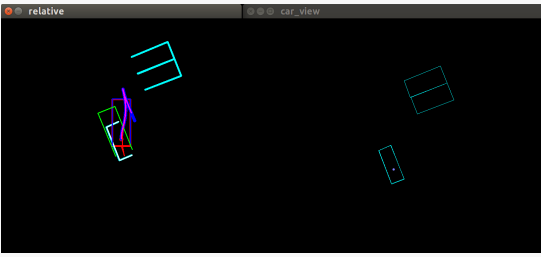


compare 0514

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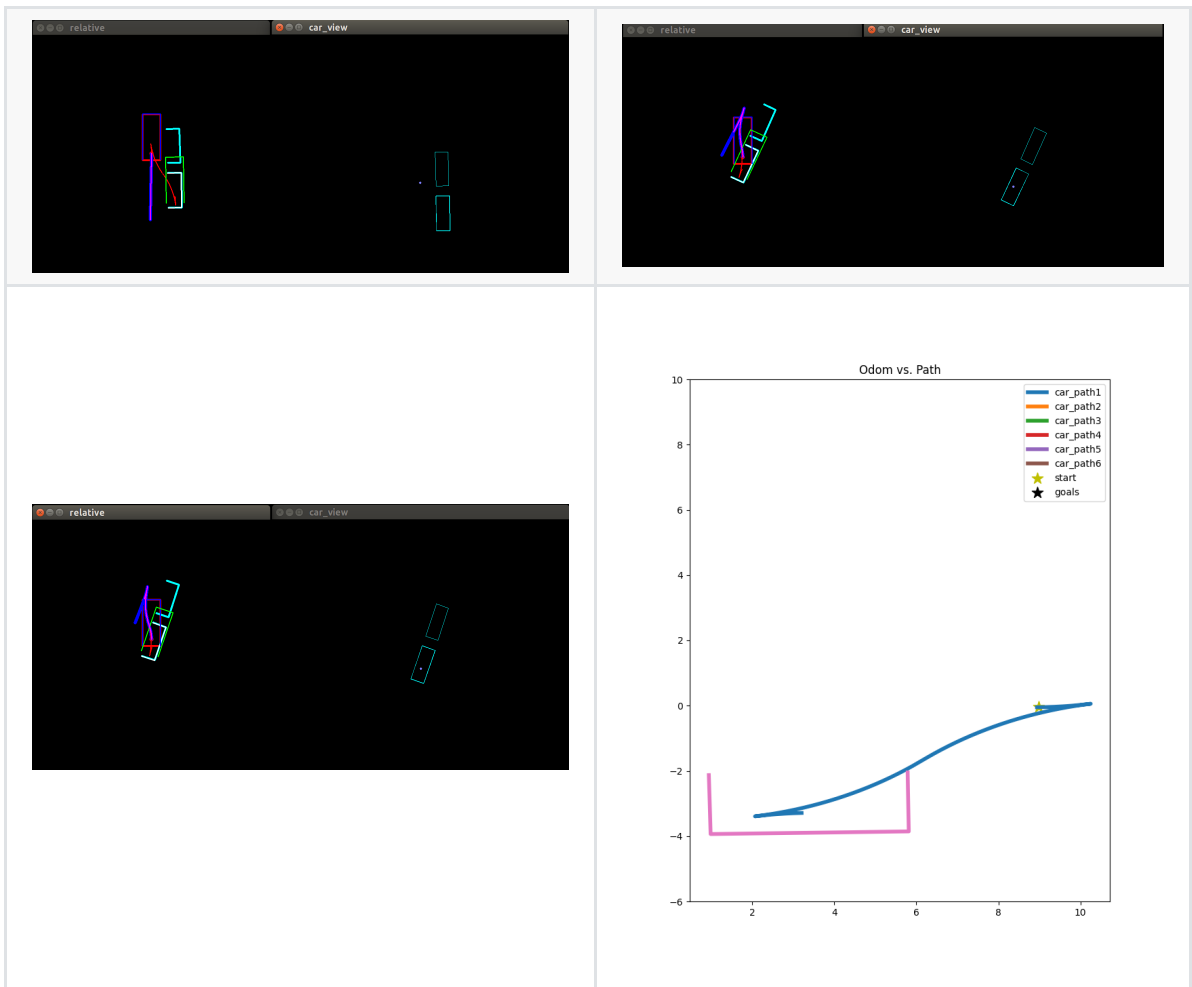
```
computed_path_01.txt (-/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_2_left_14)
Open - Save
x y theta steer
9.230823 -0.026339 -0.006000 -0.300000
9.282521 -0.026805 -0.011748 -0.300000
9.335015 -0.027573 -0.017497 -0.300000
9.387505 -0.028642 -0.023246 -0.300000
9.439986 -0.030014 -0.028994 -0.300000
9.492460 -0.031686 -0.034743 -0.300000
9.544923 -0.033661 -0.040492 -0.300000
9.597373 -0.035937 -0.046241 -0.300000
9.649810 -0.038514 -0.051989 -0.300000
9.702230 -0.041393 -0.057738 -0.300000
9.754634 -0.044573 -0.063487 -0.300000
9.807018 -0.048055 -0.069236 -0.300000
9.859383 -0.051837 -0.074984 -0.300000
9.911723 -0.055921 -0.080733 -0.300000
9.964040 -0.060305 -0.086482 -0.300000
10.016330 -0.064990 -0.092230 -0.300000
10.068593 -0.069975 -0.097979 -0.300000
10.120826 -0.075261 -0.103728 -0.300000
10.173028 -0.080847 -0.109477 -0.300000
10.225197 -0.086733 -0.115225 -0.300000
10.277331 -0.092919 -0.120974 -0.300000
10.309121 -0.096840 -0.124482 -0.300000
10.309121 -0.096840 -0.124482 -0.300000
10.257047 -0.090172 -0.130230 -0.300000
10.205011 -0.083205 -0.135979 -0.300000
10.153017 -0.075939 -0.141728 -0.300000
Plain Text - Tab Width: 8 - Ln 1, Col 1 - INS
```

```
computed_path_01.txt (-/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_2_left_14)
Open - Save
3.202766 2.472736 -0.153171 -0.300000
3.150858 2.480597 -0.147423 -0.300000
3.098906 2.488159 -0.141674 -0.300000
3.046911 2.495423 -0.135925 -0.300000
2.994875 2.502387 -0.130177 -0.300000
2.943287 2.508992 -0.124482 -0.300000
2.943287 2.508992 -0.124482 -0.300000
2.995399 2.502623 -0.118733 -0.300000
3.047547 2.496554 -0.112984 -0.300000
3.099729 2.490785 -0.107235 -0.300000
3.151943 2.485316 -0.101487 -0.300000
3.204188 2.480147 -0.095738 -0.300000
3.256462 2.475279 -0.089989 -0.300000
3.308763 2.470711 -0.084240 -0.300000
3.361089 2.466444 -0.078492 -0.300000
3.413439 2.462478 -0.072743 -0.300000
3.465811 2.458813 -0.066994 -0.300000
3.518203 2.455449 -0.061246 -0.300000
3.570613 2.452386 -0.055497 -0.300000
3.623040 2.449625 -0.049748 -0.300000
3.675483 2.447165 -0.043999 -0.300000
3.727938 2.445006 -0.038251 -0.300000
3.780405 2.443150 -0.032502 -0.300000
3.832882 2.441594 -0.026753 -0.300000
3.885367 2.440341 -0.021004 -0.300000
3.937858 2.439389 -0.015256 -0.300000
3.985522 2.438786 -0.010036 -0.300000
Plain Text - Tab Width: 8 - Ln 1, Col 1 - INS
```

```
computed_path.txt (-/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_2_left_14) - gedit
Open - Save
car_param.yaml computed_path.txt
x y theta steer
9.230823 -0.026339 -0.006000 -0.300000
9.282521 -0.026805 -0.011748 -0.300000
9.335015 -0.027573 -0.017497 -0.300000
9.387505 -0.028642 -0.023246 -0.300000
9.439986 -0.030014 -0.028994 -0.300000
9.492460 -0.031686 -0.034743 -0.300000
9.544923 -0.033661 -0.040492 -0.300000
9.597373 -0.035937 -0.046241 -0.300000
9.649810 -0.038514 -0.051989 -0.300000
9.702230 -0.041393 -0.057738 -0.300000
9.754634 -0.044573 -0.063487 -0.300000
9.807018 -0.048055 -0.069236 -0.300000
9.859383 -0.051837 -0.074984 -0.300000
9.911723 -0.055921 -0.080733 -0.300000
9.964040 -0.060305 -0.086482 -0.300000
10.016330 -0.064990 -0.092230 -0.300000
10.068593 -0.069975 -0.097979 -0.300000
10.120826 -0.075261 -0.103728 -0.300000
10.173028 -0.080847 -0.109477 -0.300000
10.225197 -0.086733 -0.115225 -0.300000
10.277331 -0.092919 -0.120974 -0.300000
10.329429 -0.099405 -0.126723 -0.300000
10.381489 -0.106189 -0.132472 -0.300000
10.433508 -0.113273 -0.138220 -0.300000
10.485486 -0.120656 -0.143969 -0.300000
Plain Text - Tab Width: 8 - Ln 18, Col 31 - INS
```

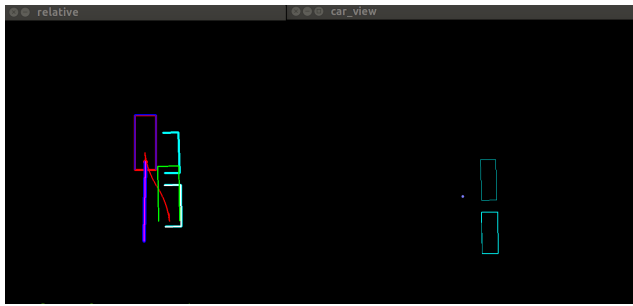
```
computed_path.txt (-/Work/TS_PC/4459_20210513/pc/dvr_0513_rs_2_left_14) - gedit
Open - Save
car_param.yaml computed_path.txt
2.709287 3.042087 -0.150905 -0.300000
2.761213 3.034344 -0.145156 -0.300000
2.813182 3.026899 -0.139407 -0.300000
2.865194 3.019754 -0.133659 -0.300000
2.917245 3.012907 -0.127910 -0.300000
2.969335 3.006360 -0.122161 -0.300000
3.021462 3.000112 -0.116412 -0.300000
3.073624 2.994164 -0.110664 -0.300000
3.125819 2.988516 -0.104915 -0.300000
3.178046 2.983168 -0.099166 -0.300000
3.230303 2.978121 -0.093417 -0.300000
3.282588 2.973374 -0.087669 -0.300000
3.334899 2.968928 -0.081920 -0.300000
3.387235 2.964782 -0.076171 -0.300000
3.439594 2.960937 -0.070423 -0.300000
3.491974 2.957394 -0.064674 -0.300000
3.544374 2.954151 -0.058925 -0.300000
3.596792 2.951210 -0.053176 -0.300000
3.649225 2.948570 -0.047428 -0.300000
3.701673 2.946232 -0.041679 -0.300000
3.754133 2.944196 -0.035930 -0.300000
3.806605 2.942460 -0.030181 -0.300000
3.859085 2.941027 -0.024433 -0.300000
3.911573 2.939895 -0.018684 -0.300000
3.964066 2.939065 -0.012935 -0.300000
3.99540 2.938761 -0.010036 -0.300000
Plain Text - Tab Width: 8 - Ln 207, Col 37 - INS
```

2. dvr\_0513\_rs\_1\_right

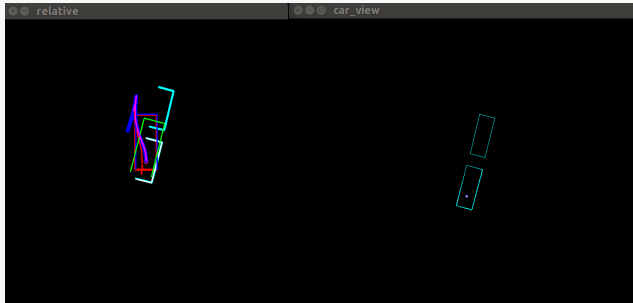
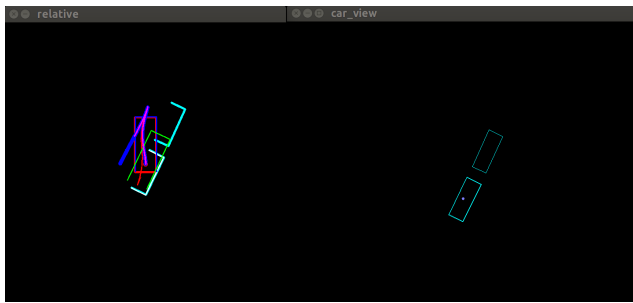
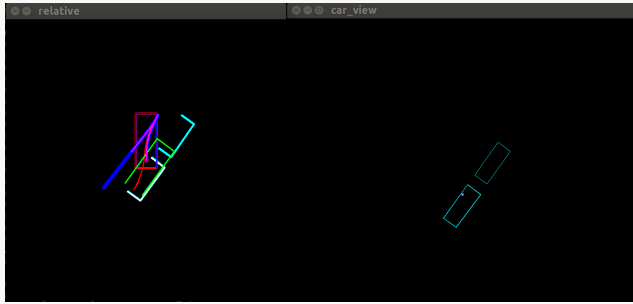


compare 0514

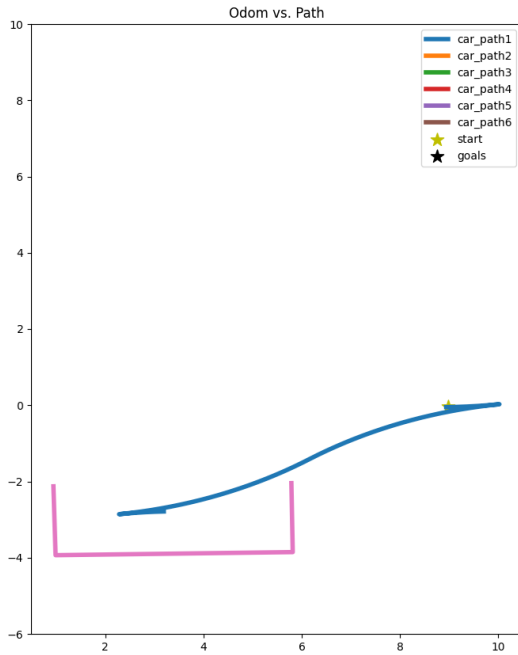
0514



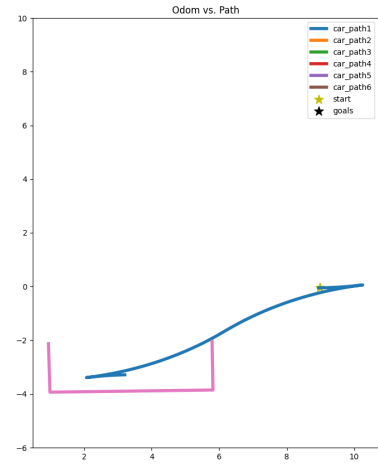
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0513



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computed_path_01.txt (~/.Work/TS_PC/4459_20210513/pc/dvr_0513_rs_1_righ
Open  Save
x y theta steer
8.940826 -0.049197 0.009714 0.300000
8.993322 -0.048536 0.015463 0.300000
9.045814 -0.047573 0.021211 0.300000
9.098298 -0.046309 0.026960 0.300000
9.150775 -0.044743 0.032709 0.300000
9.203241 -0.042875 0.038458 0.300000
9.255696 -0.040706 0.044206 0.300000
9.308138 -0.038235 0.049955 0.300000
9.360565 -0.035463 0.055704 0.300000
9.412974 -0.032389 0.061453 0.300000
9.465366 -0.029014 0.067201 0.300000
9.517737 -0.025339 0.072950 0.300000
9.570086 -0.021362 0.078699 0.300000
9.622412 -0.017084 0.084447 0.300000
9.674711 -0.012505 0.090196 0.300000
9.726984 -0.007626 0.095945 0.300000
9.779228 -0.002446 0.101694 0.300000
9.831441 0.003033 0.107442 0.300000
9.883622 0.008813 0.113191 0.300000
9.935768 0.014893 0.118940 0.300000
9.987880 0.021272 0.124689 0.300000
10.023583 0.025819 0.128630 0.300000
10.023583 0.025819 0.128630 -0.300000
9.971538 0.018935 0.134378 -0.300000
9.919531 0.011752 0.140127 -0.300000
9.867567 0.004270 0.145076 -0.300000
Plain Text  Tab Width: 8  Ln 9, Col 37  INS

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computed_path_01_13.txt (~/.Work/TS_PC/4459_20210513/pc/dvr_0513_rs_1_righ
Open  Save
x y theta steer
8.940826 -0.049197 0.009714 0.300000
8.993322 -0.048536 0.015463 0.300000
9.045814 -0.047573 0.021211 0.300000
9.098298 -0.046309 0.026960 0.300000
9.150775 -0.044743 0.032709 0.300000
9.203241 -0.042875 0.038458 0.300000
9.255696 -0.040706 0.044206 0.300000
9.308138 -0.038235 0.049955 0.300000
9.360565 -0.035463 0.055704 0.300000
9.412974 -0.032389 0.061453 0.300000
9.465366 -0.029014 0.067201 0.300000
9.517737 -0.025339 0.072950 0.300000
9.570086 -0.021362 0.078699 0.300000
9.622412 -0.017084 0.084447 0.300000
9.674711 -0.012505 0.090196 0.300000
9.726984 -0.007626 0.095945 0.300000
9.779228 -0.002446 0.101694 0.300000
9.831441 0.003033 0.107442 0.300000
9.883622 0.008813 0.113191 0.300000
9.935768 0.014893 0.118940 0.300000
9.987880 0.021272 0.124689 0.300000
10.039953 0.027951 0.130437 0.300000
10.091987 0.034929 0.136186 0.300000
10.143980 0.042207 0.141935 0.300000
10.195930 0.049783 0.147683 0.300000
10.247936 0.057467 0.153432 0.300000
Plain Text  Tab Width: 8  Ln 11, Col 12  INS

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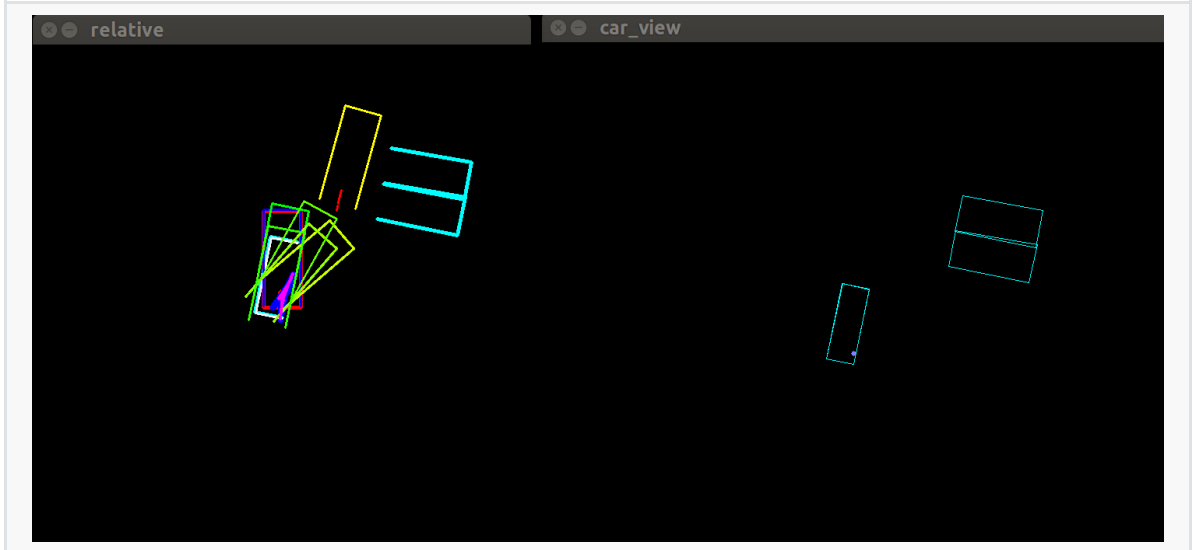
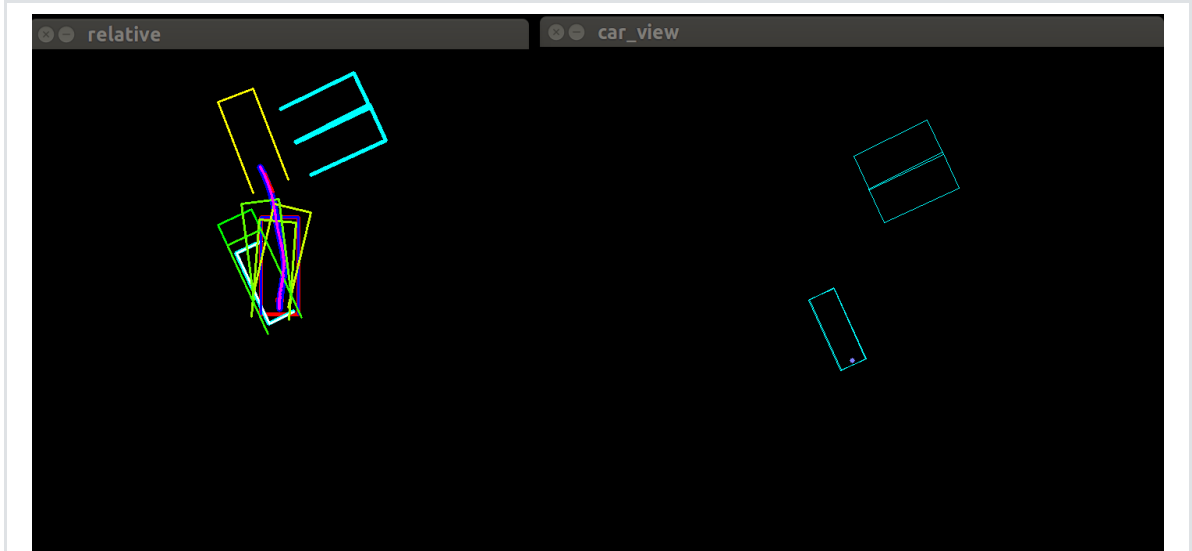
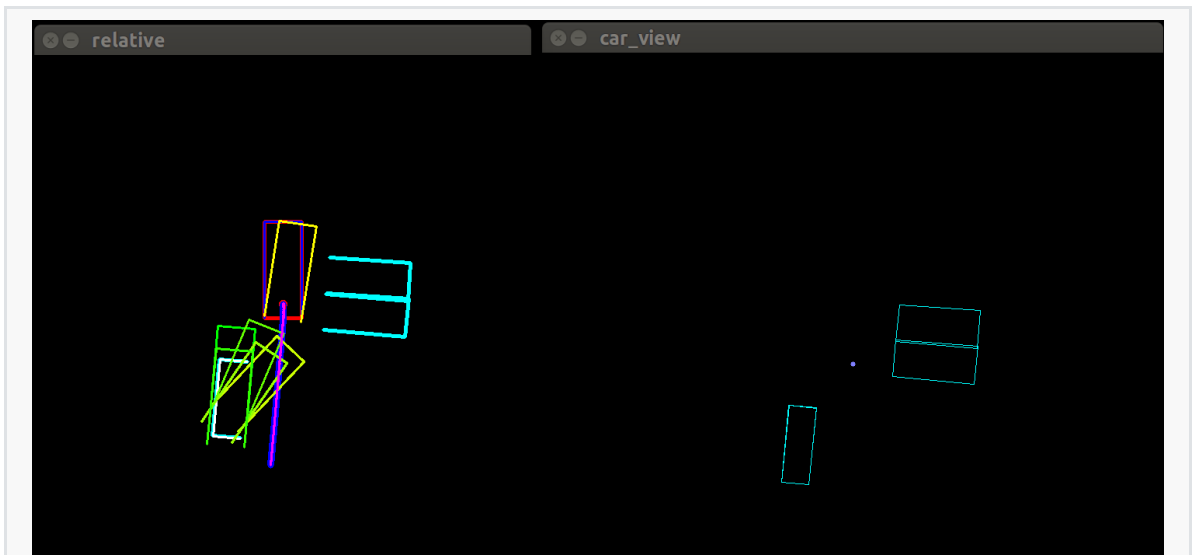
Open computed\_path\_01\_13.txt (C:\Work\T5\_PC\4459\_20210513\pc/dvr\_0513\_rs\_1) Save

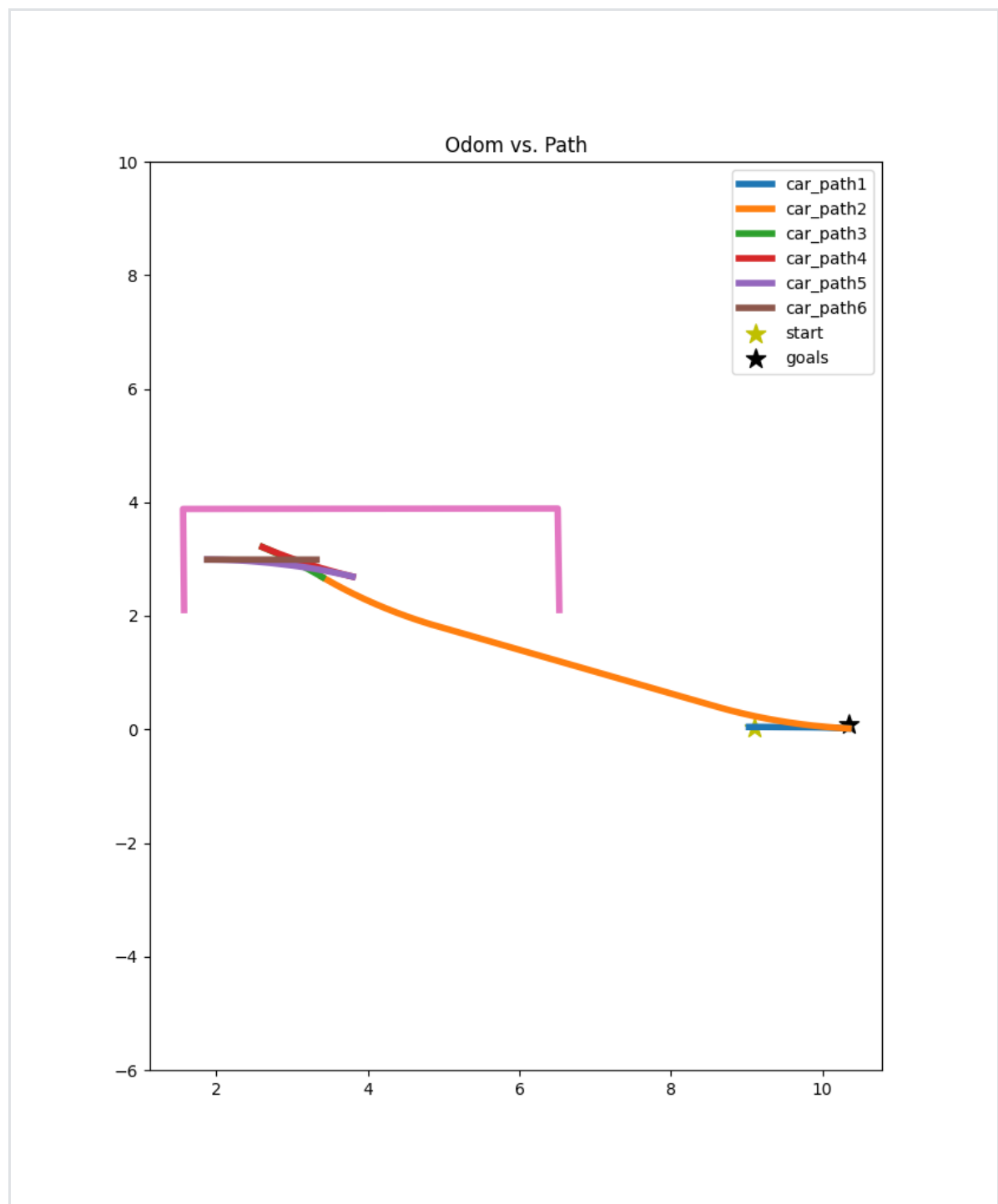
2.191472	-3.574592	0.161472	0.300000
2.142372	-3.380554	0.161723	0.300000
2.090533	-3.388859	0.155974	0.300000
2.069360	-3.392162	0.153629	0.300000
2.069360	-3.392162	0.153629	0.300000
2.121272	-3.384277	0.147880	0.300000
2.173221	-3.376691	0.142131	0.300000
2.225213	-3.369404	0.136383	0.300000
2.272246	-3.362415	0.130634	0.300000
2.292318	-3.357576	0.124885	0.300000
2.381428	-3.349336	0.119136	0.300000
2.435373	-3.343246	0.113388	0.300000
2.485753	-3.337456	0.107639	0.300000
2.537965	-3.331966	0.101890	0.300000
2.590288	-3.326776	0.096142	0.300000
2.642479	-3.321887	0.090393	0.300000
2.694778	-3.317298	0.084644	0.300000
2.747183	-3.313010	0.078895	0.300000
2.799451	-3.309023	0.073147	0.300000
2.851821	-3.305336	0.067398	0.300000
2.904212	-3.301951	0.061649	0.300000
2.956621	-3.298867	0.055900	0.300000
3.009048	-3.296085	0.050152	0.300000
3.061449	-3.293604	0.044403	0.300000
3.113943	-3.291424	0.038654	0.300000
3.166480	-3.289546	0.032905	0.300000
3.204842	-3.288362	0.027695	0.300000

Plain Text • Tab Width: 8 • Ln 217, Col 34 • INI

### 3. dvr\_0513\_mode10\_2\_left

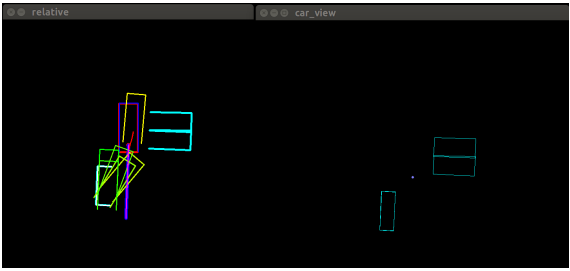




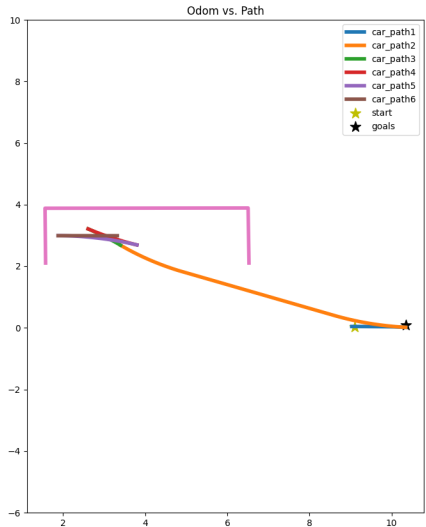
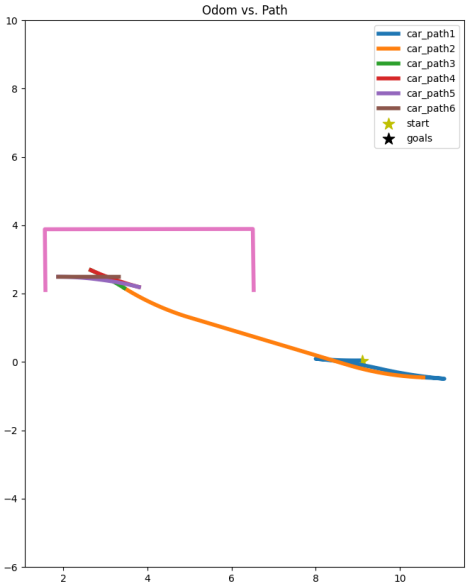


compare 0514

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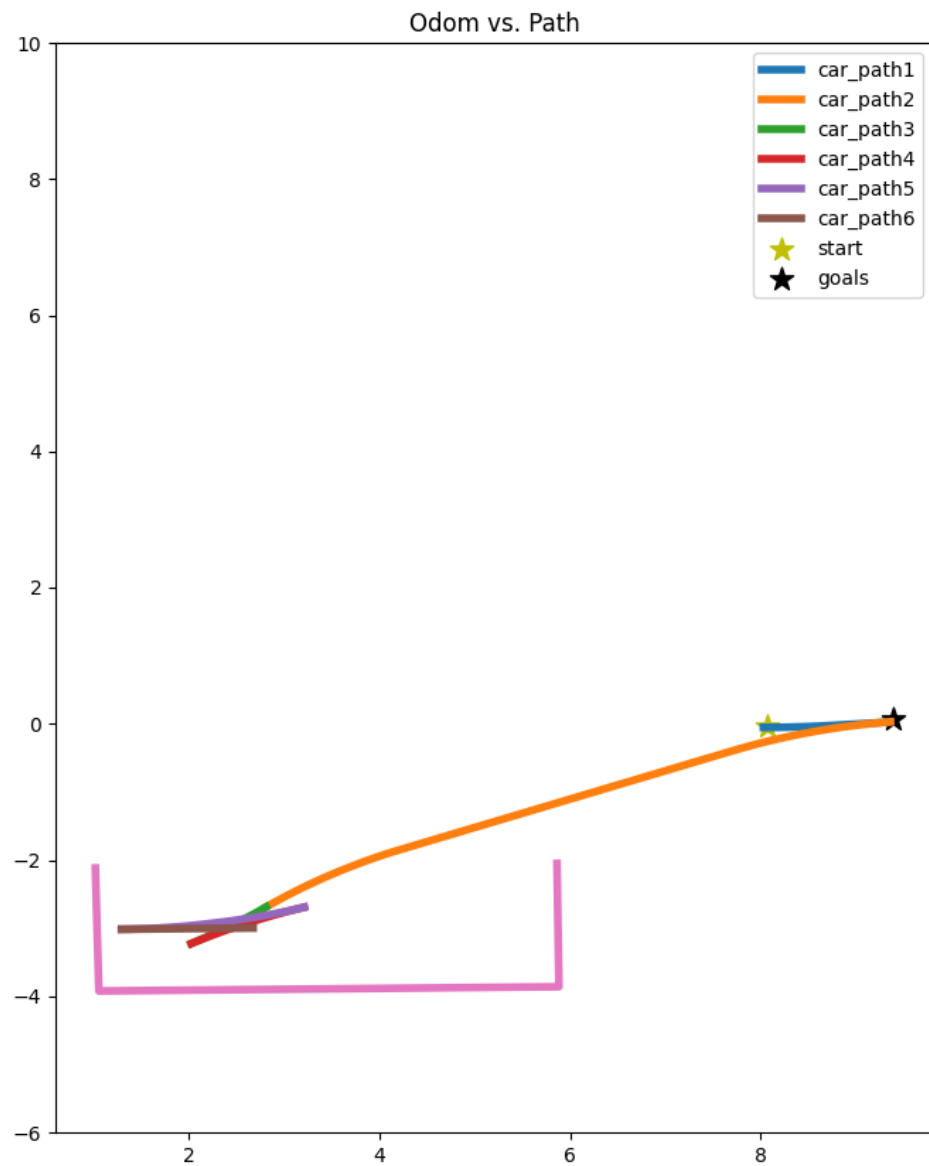
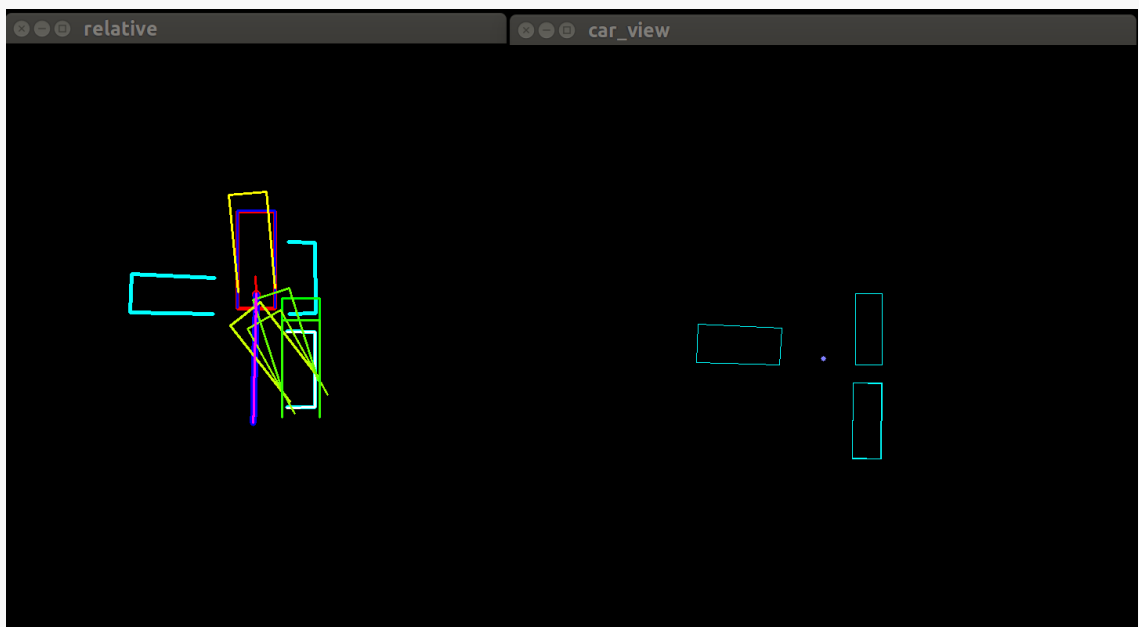
0513




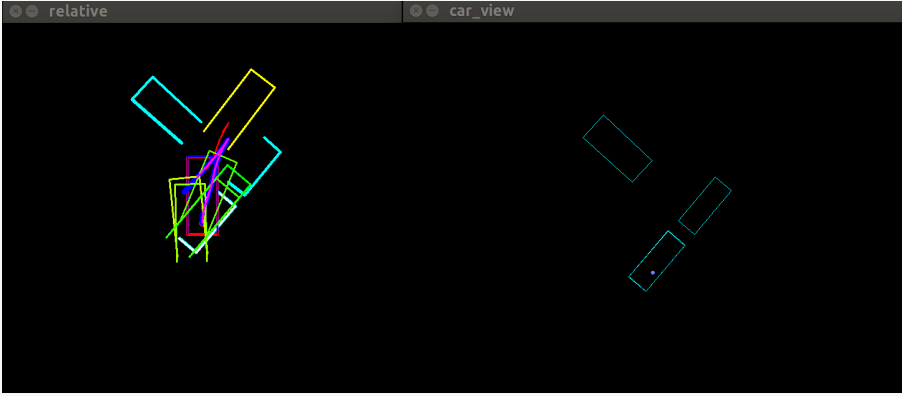
```
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: recalculating parking points A: 4.93178 0.811743 B: 3.34873 0.8136154 C: 3.154 4.98667 B: 4.93702 4.96377
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: parking spot center from APA (4.04268 2.48889)
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: parking spot length 1.78382 width 6.1 lane width 6.8 mode 10
[2021-05-14 11:47:22.552] [info] start to handle middle goals.
[2021-05-14 11:47:22.552] [info] using parking mode 10
[2021-05-14 11:47:22.552] [info] save final goal 3.21216 2.48888 0.00186455
[2021-05-14 11:47:22.552] [info] car pose 0.81178 0.842347 0.0092079
[2021-05-14 11:47:22.552] [info] theta 0.818583 dir sign 1.0
[2021-05-14 11:47:22.552] [info] street boundary 8.47463
[2021-05-14 11:47:22.552] [info] new goal added 3.88888 2.49099 -0.00106455
[2021-05-14 11:47:22.552] [info] turning radius 0.32596
[2021-05-14 11:47:22.552] [info] avoiding forward collision. Adding backward step
[2021-05-14 11:47:22.552] [info] new goal added 3.79802 2.39077 -0.00318
[2021-05-14 11:47:22.552] [info] new goal added 2.65435 2.68667 -0.546917
[2021-05-14 11:47:22.552] [info] new goal added 3.4472 2.36435 -0.657091
[2021-05-14 11:47:22.552] [info] car front corner y -3.37555
[2021-05-14 11:47:22.552] [info] new goal added 30.562 -0.455264 -0.848483
[2021-05-14 11:47:22.552] [info] relative pose -1.91026 -0.280174 0.368254
[2021-05-14 11:47:22.552] [info] relative pose 1.24188 2.72307 0.189796
[2021-05-14 11:47:22.552] [info] relative pose -0.94843 -0.071982 0.150175
[2021-05-14 11:47:22.552] [info] relative pose 7.23338 2.72308 -0.688665
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: break goal into 6 middle goals:
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 1 x: 10.562, y: -0.455264, theta: -0.848483
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 2 x: 3.4472, y: 2.36435, theta: -0.657091
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 3 x: 2.65435, y: 2.68667, theta: -0.546917
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 4 x: 3.79802, y: 2.39077, theta: -0.389318
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 5 x: 1.88888, y: 2.49099, theta: -0.00186455
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: middle goal 6 x: 3.32126, y: 2.48946, theta: -0.00186455
[2021-05-14 11:47:22.552] [info] ParkingMidIdeals: outputting goal pose layer
[2021-05-14 11:47:22.552] [info] ComputePath Forward
[2021-05-14 11:47:22.552] [info] Start pose: x: 0.81136, y: 0.842347, theta: 0.8092079, phi: 0.00151844
[2021-05-14 11:47:22.552] [info] Goal set: x: 10.562, y: -0.455264, theta: -0.848483, phi: 0.0
[2021-05-14 11:47:22.552] [info] Relative goal: x: 1.57615, y: -0.312152, theta: -0.6509888, phi: 0.0
[2021-05-14 11:47:22.552] [info] Reuse the previous path no goal.
[2021-05-14 11:47:22.552] [warning] ComputePath Map Layer name not found. Creating empty map
[2021-05-14 11:47:22.552] [info] Using SimplePathfinder
[2021-05-14 11:47:22.552] [info] Path compute time: 0.365 ms
[2021-05-14 11:47:22.552] [info] SavePathToMapInProcessStep Forward
[2021-05-14 11:47:22.552] [info] Target parking spot: A (-7.43525, 2.13117) B (-2.48342, 2.08468) C (-2.48767, 3.87159) D (-7.43111, 3.87189)
[2021-05-14 11:47:22.552] [info] GetTargetPoseParam: getting parallel parking goal
[2021-05-14 11:47:22.552] [info] SavePathToMapInProcessStep: APA goal (3.21216 2.48278 0.888912790) parking space 0
[2021-05-14 11:47:22.552] [info] GetReturnParamAssociateCenter: A (-7.46151, 2.11879) B (-2.51175, 2.87166)
[2021-05-14 11:47:22.552] [info] GetReturnParamAssociateCenter: A (-7.46151, 2.11879) B (-2.51175, 2.87166)
```

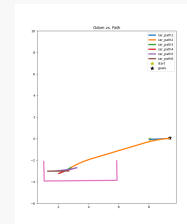
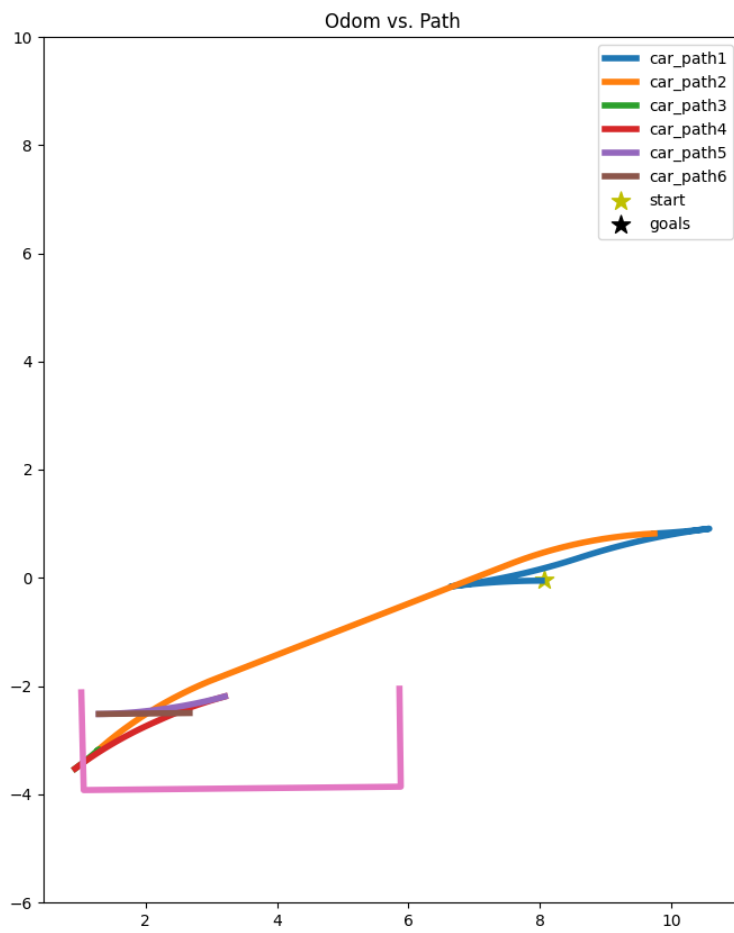
```
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: parking points A: 1.57615 2.10263 D: 1.56236 3.88169 C: 1.56684 3.88088 B: 0.3205 2.18375
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: parking spot center from APA (4.04381 2.99442)
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: parking spot length 1.79303 width 6.1 lane width 6.8 mode 10
[2021-05-13 21:54:20.397] [info] start to handle middle goals.
[2021-05-13 21:54:20.397] [info] using parking mode 10
[2021-05-13 21:54:20.397] [info] save final goal 3.32238 2.98846 -0.00186455
[2021-05-13 21:54:20.397] [info] car pose 0.81178 0.842347 0.0092079
[2021-05-13 21:54:20.397] [info] theta 0.818583 dir sign 1.0
[2021-05-13 21:54:20.397] [info] street boundary 8.49442
[2021-05-13 21:54:20.397] [info] new goal added 1.88141 2.99899 -0.00106455
[2021-05-13 21:54:20.397] [info] turning radius 0.32596
[2021-05-13 21:54:20.397] [info] avoiding forward collision. Adding backward step
[2021-05-13 21:54:20.397] [info] new goal added 1.88038 2.98777 -0.00318
[2021-05-13 21:54:20.397] [info] new goal added 2.61127 3.21852 -0.514827
[2021-05-13 21:54:20.397] [info] new goal added 3.39997 2.6254 -0.646995
[2021-05-13 21:54:20.397] [info] car front corner y -3.38205
[2021-05-13 21:54:20.397] [info] found smooth goal
[2021-05-13 21:54:20.397] [info] new goal added 10.3441 0.818126 -0.8682482
[2021-05-13 21:54:20.397] [info] relative pose -1.91026 -0.280174 0.368254
[2021-05-13 21:54:20.397] [info] relative pose 1.24087 0.13187 0.205562
[2021-05-13 21:54:20.397] [info] relative pose -0.94843 -0.071982 0.150175
[2021-05-13 21:54:20.397] [info] relative pose 7.19881 2.18666 -0.596747
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: break goal into 6 middle goals:
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 1 x: 10.3441, y: 0.818126, theta: -0.8682482
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 2 x: 3.39997, y: 2.6254, theta: -0.646995
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 3 x: 2.61127, y: 3.21852, theta: -0.514827
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 4 x: 3.38025, y: 2.69877, theta: -0.389318
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 5 x: 1.88141, y: 2.99899, theta: -0.00186455
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: middle goal 6 x: 3.32238, y: 2.99846, theta: -0.00186455
[2021-05-13 21:54:20.397] [info] ParkingMidIdeals: outputting goal pose layer
[2021-05-13 21:54:20.397] [info] CompletePath Forward
[2021-05-13 21:54:20.397] [info] Start pose: x: 0.81136, y: 0.842347, theta: 0.8092079, phi: 0.00151844
[2021-05-13 21:54:20.397] [info] Goal set: x: 10.3441, y: 0.818126, theta: -0.8682482, phi: 0.0
[2021-05-13 21:54:20.397] [info] Relative goal: x: 1.31244, y: -0.0387197, theta: -0.0777688, phi: 0.0
[2021-05-13 21:54:20.397] [info] Reuse the previous path no goal.
[2021-05-13 21:54:20.397] [warning] ComputePath Map Layer name not found. Creating empty map
[2021-05-13 21:54:20.397] [info] Using SimplePathfinder
[2021-05-13 21:54:20.397] [info] Path compute time: 0.365888 ms
[2021-05-13 21:54:20.397] [info] SavePathToMapInProcessStep Forward
[2021-05-13 21:54:20.397] [info] Target parking spot: A (-7.43525, 2.13117) B (-2.48342, 2.08468) C (-2.48767, 3.87189) D (-7.43111, 3.87189)
[2021-05-13 21:54:20.397] [info] GetTargetPoseParam: getting parallel parking goal
[2021-05-13 21:54:20.397] [info] SavePathToMapInProcessStep: APA goal (3.31758 2.99376 0.888912790) parking space 0
```

#### 4. dvr\_0513\_mode10\_1\_right

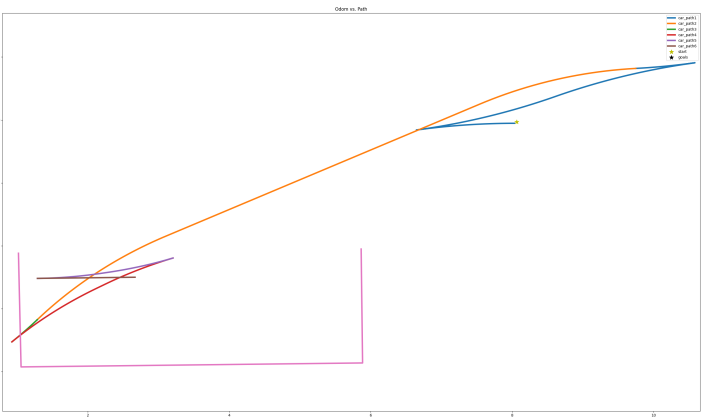
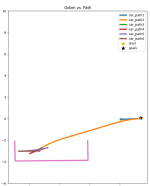
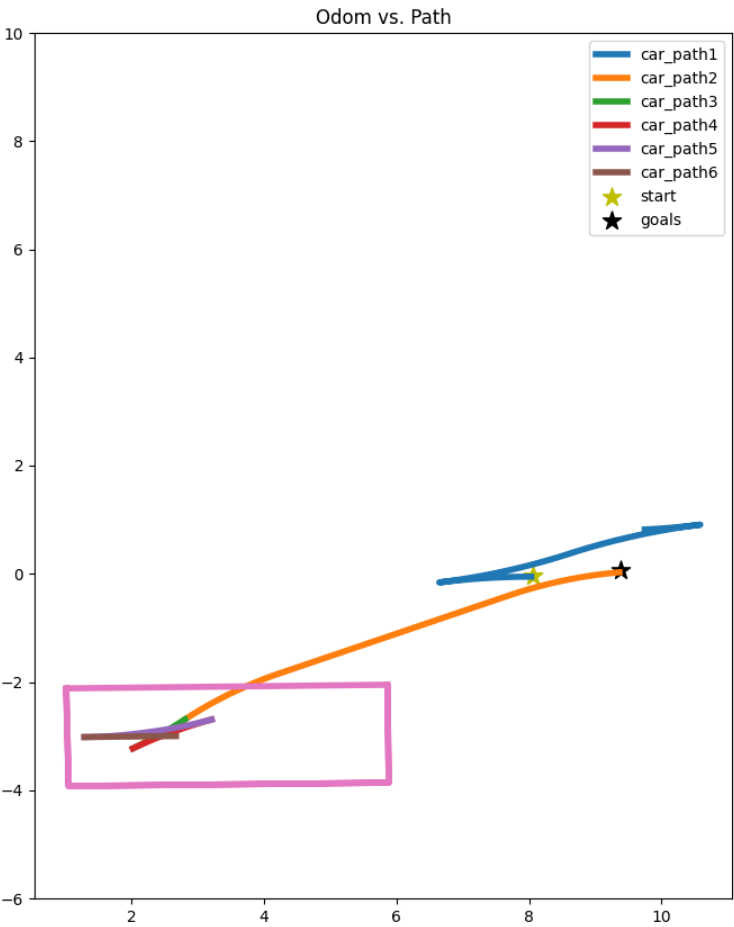


**compare 0514**

0514	0513
	
	







```
pc_log log --drv 0513 mode10 1.rght.14
[2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot center from APA (3.4564 -2.98883)
[2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot length 1.88843 width 6.1 lane width 6.0 mode 10
[2021-05-13 22:31:49.534] [info] start to handle middle goals.
[2021-05-13 22:31:49.534] [info] Using parking mode 10
[2021-05-13 22:31:49.534] [info] save final goal 2.87497 2.99934 0.8134442
[2021-05-13 22:31:49.534] [info] car pose 0.83187 -0.6532898 0.00057375
[2021-05-13 22:31:49.534] [info] theta -0.0128689 dir sign -1.0
[2021-05-13 22:31:49.534] [info] street boundary 6.9817
[2021-05-13 22:31:49.534] [info] new goal added 1.29459 -3.0179 0.0134442
[2021-05-13 22:31:49.534] [info] turning radius 6.32596
[2021-05-13 22:31:49.534] [info] avoiding forward collision. Adding backward step
[2021-05-13 22:31:49.534] [info] new goal added 1.21197 -2.69392 0.321698
[2021-05-13 22:31:49.534] [info] new goal added 2.62535 -3.22839 0.5272
[2021-05-13 22:31:49.534] [info] new goal added 2.8116 -2.6964 0.077375
[2021-05-13 22:31:49.534] [info] car front corner y 3.37632
[2021-05-13 22:31:49.542] [info] found on goal
[2021-05-13 22:31:49.542] [info] new goal added 9.36332 0.6283884 0.188292
[2021-05-13 22:31:49.542] [info] relative pose -1.92145 0.258871 -0.386254
[2021-05-13 22:31:49.542] [info] relative pose 1.29441 -0.183162 -0.265562
[2021-05-13 22:31:49.542] [info] relative pose -0.949696 0.0737512 -0.158175
[2021-05-13 22:31:49.542] [info] relative pose -0.88722 -1.09409 0.569883
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: break goal into 6 middle goals:
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 1 x: 9.36332, y: 0.6283884, theta: 0.188292
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 2 x: 2.8116, y: -2.6964, theta: 0.677375
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 3 x: 2.62535, y: -3.22839, theta: 0.5272
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 4 x: 3.21197, y: -2.69392, theta: 0.321698
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 5 x: 1.29459, y: -3.0179, theta: 0.0134442
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 6 x: 2.8116, y: -2.6964, theta: 0.8134442
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: outputting goal pose layer
[2021-05-13 22:31:49.542] [info] ComputePath Forward
[2021-05-13 22:31:49.542] [info] Start pose: x: 0.83187, y: -0.6532898, theta: 0.00057375, phi: 0.00961676
[2021-05-13 22:31:49.542] [info] goal set x: 9.36332, y: 0.628388, theta: 0.188292, phi: 0.0
[2021-05-13 22:31:49.542] [info] Relative goal: x: 1.33149, y: 0.0809118, theta: 0.187177, phi: 0.0
[2021-05-13 22:31:49.542] [info] Resume the previous path no goal.
[2021-05-13 22:31:49.542] [warning] ComputePath Map layer name not found. Creating empty map

pc_log log --drv 0513 mode10 1.rght.14
[2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot center from APA (3.4564 -2.98883)
[2021-05-13 22:31:49.534] [info] ParkingMiddleGoals: parking spot length 1.88843 width 6.1 lane width 6.0 mode 10
[2021-05-13 22:31:49.534] [info] start to handle middle goals.
[2021-05-13 22:31:49.534] [info] Using parking mode 10
[2021-05-13 22:31:49.534] [info] save final goal 2.87497 2.99934 0.8134442
[2021-05-13 22:31:49.534] [info] car pose 0.83187 -0.6532898 0.00057375
[2021-05-13 22:31:49.534] [info] theta -0.0128689 dir sign -1.0
[2021-05-13 22:31:49.534] [info] street boundary 6.9817
[2021-05-13 22:31:49.534] [info] new goal added 1.29459 -3.0179 0.0134442
[2021-05-13 22:31:49.534] [info] turning radius 6.32596
[2021-05-13 22:31:49.534] [info] avoiding forward collision. Adding backward step
[2021-05-13 22:31:49.534] [info] new goal added 1.21197 -2.69392 0.321698
[2021-05-13 22:31:49.534] [info] new goal added 2.62535 -3.22839 0.5272
[2021-05-13 22:31:49.534] [info] new goal added 2.8116 -2.6964 0.077375
[2021-05-13 22:31:49.534] [info] car front corner y 3.37632
[2021-05-13 22:31:49.542] [info] found on goal
[2021-05-13 22:31:49.542] [info] new goal added 9.36332 0.6283884 0.188292
[2021-05-13 22:31:49.542] [info] relative pose -1.92145 0.258871 -0.386254
[2021-05-13 22:31:49.542] [info] relative pose 1.29441 -0.183162 -0.265562
[2021-05-13 22:31:49.542] [info] relative pose -0.949696 0.0737512 -0.158175
[2021-05-13 22:31:49.542] [info] relative pose -0.88722 -1.09409 0.569883
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: break goal into 6 middle goals:
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 1 x: 9.36332, y: 0.6283884, theta: 0.188292
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 2 x: 2.8116, y: -2.6964, theta: 0.677375
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 3 x: 2.62535, y: -3.22839, theta: 0.5272
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 4 x: 3.21197, y: -2.69392, theta: 0.321698
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 5 x: 1.29459, y: -3.0179, theta: 0.0134442
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: middle goal 6 x: 2.8116, y: -2.6964, theta: 0.8134442
[2021-05-13 22:31:49.542] [info] ParkingMiddleGoals: outputting goal pose layer
[2021-05-13 22:31:49.542] [info] ComputePath Forward
[2021-05-13 22:31:49.542] [info] Start pose: x: 0.83187, y: -0.6532898, theta: 0.00057375, phi: 0.00961676
[2021-05-13 22:31:49.542] [info] goal set x: 9.36332, y: 0.628388, theta: 0.188292, phi: 0.0
[2021-05-13 22:31:49.542] [info] Relative goal: x: 1.33149, y: 0.0809118, theta: 0.187177, phi: 0.0
[2021-05-13 22:31:49.542] [info] Resume the previous path no goal.
[2021-05-13 22:31:49.542] [warning] ComputePath Map layer name not found. Creating empty map
```